What is claimed is:

1. A method of teaching a traveling path to a robot, wherein in teaching a traveling path to an autonomously traveling robot,

a teaching object moves, the robot monitors a position of the teaching object in time series and detects a movement of the teaching object based on data on time-series positional changes, and the robot moves according to the data on positional changes of the teaching object, and

the robot detects a traveling direction and travel distance of the robot, accumulates the direction and distance in time series, and converts the direction and distance into path teaching data.

2. A method of teaching a traveling path to a robot, wherein in teaching a traveling path to an autonomously traveling robot,

a teaching object moves, the robot autonomously travels according to taught path teaching data,

the robot monitors a position of the teaching object in time series, detects a movement of the teaching object based on data on time-series positional change of the object, and checks the traveling path of the teaching object, and the robot moves while correcting the taught path teaching data, and

the robot detects a traveling direction and travel distance of the robot, accumulates the direction and distance in time series, and converts the direction and distance into path teaching data.

3. A robot having a function of learning a traveling path, comprising:

a position detecting unit for detecting a position of a teaching object;

a movement detecting unit for monitoring the position of the teaching object in time series and detecting a movement of the teaching object based on data on time-series positional changes;

a moving unit for moving the robot according to the data on positional changes of the teaching object;

a movement detecting unit for detecting a traveling direction and travel distance of the robot; and

a data converting unit for accumulating the movement in time series and converting the movement into path teaching data.

4.   A robot having a function of learning a traveling path, comprising:

a position detecting unit for detecting a position of a teaching object;

a movement detecting unit for monitoring the position of the teaching object in time series and detecting a movement of the teaching object based on data on time-series positional changes of the object;

a moving unit for moving the robot according to taught path teaching data of the robot; and

a control unit for checking a traveling path of the teaching object, moving the robot while correcting the taught path teaching data, learning the traveling path of the teaching object while correcting the taught path teaching data, and determining the path teaching data.

5.　The robot having a function of learning a traveling path according to claim 3 or 4, wherein the position detecting unit for detecting a position of the teaching object detects, by using an array antenna, a signal of a transmitter carried by the teaching object, whereby the position of the teaching object is detected.

6.　The robot having a function of learning a traveling path according to claim 3 or 4, wherein the position detecting unit for detecting a position of the teaching object takes an image of the teaching object by using a camera, specifies a teaching object image in a photographing frame, and detects the position of the teaching object based on a movement of the teaching object image.

7.　The robot having a function of learning a traveling path according to claim 3 or 4, wherein the position detecting unit for detecting a position of the teaching object detects the position of the teaching object by using a sound source direction detecting unit comprising a directivity sound input member, a signal direction detecting section, and a direction confirmation control section.

8.　The robot having a function of learning a traveling path according to claim 3 or 4, wherein the position detecting unit for detecting a position of the teaching object detects a direction of a position where the teaching object contacts the robot, whereby the position of the teaching object is detected.